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cont/ core 214. The alternating magnetic flux flowing through the magnetic core 214 induces a secondary alternating current in the secondary coil 224. The secondary alternating current is routed to the electronics circuit 212 where it is rectified to provide direct current electrical power throughout the robot 200. Referring back to FIG. 1 momentarily, the alternating current flowing in the primary coils 122 is generated by a power supply 124.

Please replace the paragraph beginning on page 14, at line 16 with the paragraph shown below:

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Electrically, the second alternating currents induced in both secondary coils 224 and 240 can be added by connecting both secondary coils 224 and 240 together. This configuration, however, requires that all of the alternating currents applied to the primary coils 122 are in phase with each other. If not, the secondary alternating current induced in the secondary coil 224 may add destructively with a second secondary alternating current induced in the second secondary coil 240. In the preferred embodiment, each secondary alternating current is rectified individually before being combined, as shown in FIG. 12. The secondary coil 224 is connected to a first full wave bridge rectifier 242. The second secondary coil 240 is connected to a second full wave bridge rectifier 244. Other types of rectifiers may also be used within the scope of the present invention. The outputs of each full wave bridge rectifier 242 and 244 are connected together and filtered by a capacitor 246 or other type of filter. If a battery 226 is included in the robot 200, it is also connected to the output of the full wave bridge rectifiers 242 and 244 at this point. Finally, the resulting direct current electrical power is provided to the electronics circuit 212 and any other load in the robot 200 requiring electrical power.

Please replace the paragraph beginning on page 15, at line 13 with the paragraph shown below:

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Knowledge of when to switch on and switch off the alternating current to the various primary coils 122 may be provided by the controller 114. The controller 114 knows the location of each robot 200 within the automated library system 100 and thus which primary coil or coils 122 each robot 200 is adjacent to, is approaching, and has departed. The controller 114 may use this knowledge to issue commands to the switching unit 136 that